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AMENDMENTS TO THE CLAIMS

The following listing of claims will replace all prior versions, and listings, of claims in the application:

Listing of Claims:

1. (Original) A control device of a legged mobile robot adapted to sequentially determine instantaneous values of a desired motion and a desired floor reaction force of a legged mobile robot that travels by moving legs extended from its body by using a dynamic model that expresses a relationship between at least a motion of the robot and a floor reaction force, and also to control an operation of the robot at the same time so as to make the robot follow the determined instantaneous values of the desired motion and the desired floor reaction force, comprising:

permissible range setting means for setting a permissible range of a restriction object amount, the restriction object amount being a vertical component of a floor reaction force moment or a component of the floor reaction force moment in floor surface normal line direction to be applied to a robot in operation, following the desired motion and the desired floor reaction force; and

desired instantaneous value determining means for determining, on the basis of at least a difference between a desired state amount related to a posture of the robot about a vertical axis or about a floor surface normal line axis and an actual state amount of the robot and the permissible range, instantaneous values of the desired motion and the desired floor reaction force such that a deviation between a

floor reaction force moment balancing with the desired motion on the dynamic model and a floor reaction force moment of the desired floor reaction force approximates the difference to zero, while having the restriction object amount, which is associated with the desired floor reaction force, fall within the permissible range.

2. (Original) The control device of a legged mobile robot according to Claim 1, wherein the desired instantaneous value determining means comprises means for determining a compensating floor reaction force moment, which is an additional floor reaction force moment for approximating the difference to zero on the basis of the difference, and means for determining a correction amount of a predetermined provisional instantaneous value such that the restriction object amount does not exceed the permissible range on the basis of at least a floor reaction force moment that balances with the predetermined provisional instantaneous value of the desired motion on the dynamic model and the compensating floor reaction force moment, wherein the provisional instantaneous value is corrected on the basis of the determined correction amount so as to determine an instantaneous value of the desired motion.

3. (Original) The control device of a legged mobile robot according to Claim 2, further comprising means for determining a model correction floor reaction force moment, which is an additional floor reaction force moment for approximating a state amount of the dynamic model to a predetermined state amount, wherein the means for determining a correction amount of a predetermined provisional instantaneous value of the desired motion determines a correction amount of a provisional

instantaneous value of the desired motion such that the restriction object amount does not exceed the permissible range on the basis of at least a floor reaction force moment that balances with the predetermined provisional instantaneous value on the dynamic model, the compensating floor reaction force moment, and the model correction floor reaction force moment.

4. (Currently Amended) The control device of a legged mobile robot according to Claim 2-~~or~~3, wherein the correction amount of the predetermined provisional instantaneous value is a correction amount of a motion that changes a vertical component or a component in floor surface normal line direction of an angular momentum changing rate of the robot.

5. (Original) The control device of a legged mobile robot according to Claim 4, wherein the motion that changes the vertical component or the component in floor surface normal line direction of the angular momentum changing rate of the robot is a motion of a body of the robot and/or an arm extended from the body of the robot.

6. (Original) A control device of a legged mobile robot adapted to sequentially determine an instantaneous value of a desired motion of a legged mobile robot that travels by moving legs extended from its body by using a dynamic model that expresses a relationship between at least a motion of the robot and a floor reaction force, and also to control an operation of the robot at the same time so as to make the robot follow the determined instantaneous value of the desired motion, comprising:

permissible range setting means for setting a permissible range of a restriction object amount, the restriction object amount being a vertical component of a floor reaction force moment or a component of the floor reaction force moment in floor surface normal line direction to be applied to a robot in operation, following the desired motion;

compensating floor reaction force moment determining means for determining a compensating floor reaction force moment, which is an additional floor reaction force moment for bringing a difference between a desired state amount related to a posture of the robot about a vertical axis or a floor surface normal line axis and an actual state amount of the robot close to zero on the basis of at least the difference; and

desired instantaneous value determining means for determining an instantaneous value of the desired motion such that the restriction object amount, which is determined on the basis of a floor reaction force moment balancing with the desired motion on the dynamic model and the compensating floor reaction force moment, falls within the permissible range.

7. (Original) The control device of a legged mobile robot according to Claim 6, further comprising means that defines the restriction object amount falling within the permissible range as a desired floor reaction force moment, and controls the operation of the robot so as to make the robot follow the desired floor reaction force moment.

8. (Currently Amended) The control device of a legged mobile robot

according to Claim 6-~~or~~7, wherein the desired instantaneous value determining means determines an instantaneous value of the desired motion by adjusting a motion that changes a vertical component or a component in floor surface normal line direction of an angular momentum changing rate of the robot among motions of the robot in order to hold the restriction object amount, which depends on a floor reaction force moment balancing with the desired motion on the dynamic model and the compensating floor reaction force moment, within the permissible range.

9. (Original) The control device of a legged mobile robot according to Claim 8, wherein the motion that changes a vertical component or a component in floor surface normal line direction of an angular momentum changing rate of the robot is a motion of a body of the robot and/or an arm extended from the body.

10. (Original) A control device of a legged mobile robot adapted to sequentially determine an instantaneous value of a desired motion of a legged mobile robot that travels by moving legs extended from its body by using a dynamic model expressing at least a relationship between a motion of the robot and a floor reaction force, and also to control an operation of the robot at the same time so as to make the robot follow the determined instantaneous value of the desired motion, comprising:

permissible range setting means for setting a permissible range of a restriction object amount, the restriction object amount being a vertical component of a floor reaction force moment or a component of the floor reaction force moment in floor surface normal line direction to be applied to a robot in operation, following the

desired motion;

provisional instantaneous value determining means for sequentially
determining a provisional instantaneous value of the desired motion;

compensating floor reaction force moment determining means for determining
a compensating floor reaction force moment, which is an additional floor reaction
force moment for bringing a difference between a desired state amount related to a
posture of the robot about a vertical axis or a floor surface normal line axis and an
actual state amount of the robot close to zero on the basis of at least the difference;
and

desired instantaneous value determining means for determining an
instantaneous value of the desired motion by defining a portion of the restriction
object amount, which deviates from the permissible range, as a moment correction
manipulated variable, the restriction object amount being determined on the basis of
a floor reaction force moment balancing with a provisional instantaneous value of
the desired motion on the dynamic model and the compensating floor reaction force
moment, and by correcting the provisional instantaneous value of the desired motion
on the basis of the moment correction manipulated variable such that the deviating
portion indicates a tendency to decrease.

11. (Original) The control device of a legged mobile robot according to Claim
10, wherein the desired instantaneous value determining means determines an
instantaneous value of the desired motion by determining a correction amount of a
provisional instantaneous value of the desired motion on the basis of a result
obtained by passing the moment correction manipulated variable through a low-pass

filter, and then by correcting the provisional instantaneous value on the basis of the determined correction amount.

12. (Original) The control device of a legged mobile robot according to Claim 10, further comprising means for defining, as a desired floor reaction force moment, a floor reaction force moment corresponding to an already restricted restriction object amount that has been limited by restricting the restriction object amount, which is determined on the basis of a floor reaction force moment balancing with a provisional instantaneous value of the desired motion on the dynamic model and the compensating floor reaction force moment, to fall within the permissible range, and for controlling an operation of a robot so as to make the robot follow the desired floor reaction force moment.

13. (Currently Amended) The control device of a legged mobile robot according to ~~any one of Claims 10 to 12~~claim 10, wherein the desired instantaneous value determining means determines an instantaneous value of the desired motion by correcting a motion for changing a vertical component or a component in floor surface normal line direction of an angular momentum changing rate of the robot on the basis of a provisional instantaneous value of the desired motion.

14. (Original) The control device of a legged mobile robot according to Claim 13, wherein the motion for changing a vertical component or a component in floor surface normal line direction of an angular momentum changing rate of the robot is a motion of a body of the robot and/or an arm extended from the body.

15. (Currently Amended) The control device of a legged mobile robot according to ~~any one of Claims 1, 6 and 10~~claim 1, wherein the state amount related to a posture of the robot includes a yaw angle or a yaw angular velocity of the body of the robot.

16. (Currently Amended) The control device of a legged mobile robot according to ~~any one of Claims 1, 6 and 10~~claim 1, further comprising slippage determining means for determining occurrence of a slippage of the robot, wherein the permissible range setting means variably sets the permissible range according to a determination result of the slippage determining means.

17. (Original) The control device of a legged mobile robot according to Claim 16, wherein the slippage determining means determines the occurrence of a slippage on the basis of at least the ground speed of a distal portion of a leg in contact with the ground.

18. (Original) The control device of a legged mobile robot according to Claim 16, wherein the slippage determining means comprises means for determining, on the basis of at least a temporal changing rate of an actual floor reaction force acting on a leg in contact with the ground and the ground speed of a distal portion of the leg, an apparent spring constant of the leg, and determines the occurrence of a slippage on the basis of at least the apparent spring constant.

19. (Original) The control device of a legged mobile robot according to Claim 16, wherein the slippage determining means determines the occurrence of a slippage on the basis of at least a result obtained by passing an actual floor reaction force acting on a leg in contact with the ground through a band-pass filter having a frequency passing characteristic in a range near a predetermined frequency.

20. (Original) A control device that generates a desired gait of a legged mobile robot that travels by moving a plurality of legs extended from its body, and controls an operation of the robot so as to make the robot follow the desired gait, comprising:

means for determining a compensating floor reaction force moment, which is an additional floor reaction force moment for bringing a difference between a desired state amount related to a posture of the robot about a vertical axis or a floor surface normal line axis and an actual state of the robot close to zero on the basis of at least the difference;

permissible range setting means for setting a permissible range of a restriction object amount, the restriction object amount being a vertical component of a floor reaction force moment or a component of the floor reaction force moment in floor surface normal line direction to be applied to a robot in operation, following the desired gait;

provisional instantaneous value determining means for determining a provisional instantaneous value of a desired motion constituting the desired gait;

model calculating means that inputs at least a provisional instantaneous value of the desired motion to a dynamic model representing a relationship between a

motion of the robot and a vertical component or a component in floor surface normal line direction of a floor reaction force moment balancing with the motion so as to determine a vertical component or a component in floor surface normal line direction of a floor reaction force moment as an output of the dynamic model, and then determines an instantaneous value of a model restriction object amount, which is a provisional instantaneous value of the restriction object amount by carrying out predetermined calculation from the determined vertical component or the component in floor surface normal line direction and the compensating floor reaction force moment; and

desired instantaneous value determining means for determining an instantaneous value of the desired motion by correcting a provisional instantaneous value of the desired motion such that at least the instantaneous value of the model restriction object amount falls within the permissible range.

21. (Original) The control device of a legged mobile robot according to Claim 20, wherein the desired instantaneous value determining means determines a floor reaction force moment instantaneous value corresponding to an instantaneous value of a restriction object amount, which is determined by the predetermined calculation from a vertical component or a component in floor surface normal line direction of a floor reaction force moment substantially balancing with an instantaneous value of the desired motion on the dynamic model and the compensating floor reaction force moment, as an instantaneous value of a floor reaction force moment of a desired floor reaction force constituting the desired gait.

22. (Original) The control device of a legged mobile robot according to Claim 20, wherein the desired instantaneous value determining means comprises:

a perturbation model representing a relationship between a perturbative motion of the robot and a perturbative portion of a vertical component or a component in floor surface normal line direction of a floor reaction force moment;

means for determining a perturbation model manipulated variable for manipulating a perturbative portion of the perturbation model on the basis of at least the determined instantaneous value of the model restriction object amount and the permissible range;

means for determining a correction amount of the desired motion by supplying the determined perturbation model manipulated variable to the perturbation model; and

means for determining an instantaneous value of the desired motion by correcting a provisional instantaneous value of the desired motion by using the correction amount.

23. (Original) The control device of a legged mobile robot according to Claim 22, wherein the means for determining the perturbation model manipulated variable comprises means for determining, on the basis of at least the determined instantaneous value of the model restriction object amount, an estimated value of the restriction object amount in a case where the perturbation model manipulated variable is assumed to be zero, and means for comparing the determined estimated value with the permissible range to determine, on the basis of the comparison, a restricted restriction object amount that has been restricted to fall within the

permissible range, and determines the perturbation model manipulated variable on the basis of at least a difference between the determined instantaneous value of the model restriction object amount and the restricted restriction object amount.

24. (Original) The control device of a legged mobile robot according to Claim 22, further comprising:

means for determining a required value of the perturbation model manipulated variable on the basis of at least a state amount of the perturbation model,

wherein the means for determining the perturbation model manipulated variable determines a perturbation model manipulated variable to be supplied to the perturbation model on the basis of at least the determined instantaneous value of the model restriction object amount, the permissible range, and the required value.

25. (Original) The control device of a legged mobile robot according to Claim 24, wherein the means for determining a required value of the perturbation model manipulated variable sequentially determines the required value according to a feedback control law on the basis of a difference between a state amount of the perturbation model and a desired value relative to the state amount.

26. (Original) The control device of a legged mobile robot according to Claim 24, wherein the means for determining the perturbation model manipulated variable comprises means for determining an estimated value of the restriction object amount in a case, where the perturbation model manipulated variable is assumed to agree

with the required value, on the basis of at least the determined instantaneous value of the model restriction object amount and the required value, and means for comparing the determined estimated value with the permissible range to determine, on the basis of the comparison, a restricted restriction object amount that has been limited to the permissible range, and determines the perturbation model manipulated variable on the basis of at least a difference between the determined instantaneous value of the model restriction object amount and the restricted restriction object amount.

27. (Original) The control device of a legged mobile robot according to Claim 22, wherein the desired instantaneous value determining means comprises means for additionally inputting a correction amount of the desired motion to the dynamic model.

28. (Original) The control device of a legged mobile robot according to Claim 22, wherein the perturbation model is a model that represents a relationship between a perturbative motion perturbing a vertical component or a component in floor surface normal line direction of an angular momentum changing rate of a robot and a perturbation portion of the restriction object amount.

29. (Original) The control device of a legged mobile robot according to Claim 28, wherein the perturbative motion is a perturbative motion that maintains the position of a center-of-gravity of the robot substantially constant.

30. (Currently Amended) The control device of a legged mobile robot according to Claim 28-~~or 29~~, wherein the perturbative motion is a perturbative motion of a body of the robot and/or an arm extended from the body.

31. (Original) A control device for generating a desired gait of a legged mobile robot that travels by moving a plurality of legs extended from its body and for controlling an operation of the robot so as to make the robot follow the desired gait, comprising:

means for determining a compensating floor reaction force moment, which is an additional floor reaction force moment for bringing a difference between a desired state amount related to a posture of the robot about a vertical axis or a floor surface normal line axis and an actual state of the robot close to zero on the basis of at least the difference;

permissible range setting means for setting a permissible range of a restriction object amount, the restriction object amount being a vertical component of a floor reaction force moment or a component in floor surface normal line direction of the floor reaction force moment to be applied to a robot in operation, following the desired gait;

a desired floor reaction force provisional instantaneous value determining means for sequentially determining a provisional instantaneous value of at least a desired floor reaction force out of a desired motion and the desired floor reaction force constituting the desired gait;

first model calculating means for inputting at least a provisional instantaneous value of the desired floor reaction force to a first dynamic model expressing a

relationship between a motion of the robot and a floor reaction force so as to sequentially determine a provisional instantaneous value of a desired motion as an output of the first dynamic model;

second model calculating means for inputting at least the provisional instantaneous value of the desired motion to a second dynamic model expressing a relationship between a motion of the robot and a vertical component or a component in floor surface normal line direction of a floor reaction force moment balancing with the motion thereby to determine the vertical component or the component in floor surface normal line direction of the floor reaction force moment as an output of the second dynamic model, and for determining an instantaneous value of a model restriction object amount, which is a provisional instantaneous value of the restriction object amount, by carrying out predetermined calculation from the determined vertical component or component in floor surface normal line direction and the compensating floor reaction force moment; and

first model input correcting means for determining a floor reaction force moment correction amount of a desired floor reaction force so as to hold at least the instantaneous value of the model restriction object amount within the permissible range, and for additionally inputting the determined floor reaction force moment correction amount to the first dynamic model,

wherein the instantaneous value of the desired motion is determined on the basis of at least the input of the second dynamic model.

32. (Original) The control device of a legged mobile robot according to Claim 31, further comprising means for determining a floor reaction force moment

instantaneous value corresponding to an instantaneous value of a restriction object amount, which is determined from a vertical component or a component in floor surface normal line direction of a floor reaction force moment substantially balancing with an instantaneous value of the desired motion on the second dynamic model and the compensating floor reaction force moment by the predetermined calculation, as an instantaneous value of a floor reaction force moment of a desired floor reaction force constituting the desired gait.

33. (Original) The control device of a legged mobile robot according to Claim 31, wherein the first model input correcting means comprises means for determining, on the basis of at least the determined instantaneous value of the model restriction object amount, an estimated value of the restriction object amount in a case where at least a floor reaction force moment correction amount of the desired floor reaction force is assumed to be zero, and means for comparing the determined estimated value with the permissible range to determine, on the basis of the comparison, a restricted restriction object amount that has been limited to the permissible range, and determines the floor reaction force moment correction amount on the basis of at least a difference between the determined instantaneous value of the model restriction object amount and the restricted restriction object amount.

34. (Original) The control device of a legged mobile robot according to Claim 31, further comprising:

means for determining a required value of a floor reaction force moment correction amount of the desired floor reaction force,

wherein the first model input correcting means comprises means for determining, on the basis of at least the determined instantaneous value of the model restriction object amount and the required value, an estimated value of the restriction object amount when at least the floor reaction force moment correction amount of the desired floor reaction force is assumed to agree with the required value, and means for comparing the determined estimated value with the permissible range, and then determining a restricted restriction object amount limited to the permissible range on the basis of the comparison, and determines the floor reaction force moment correction amount on the basis of at least a difference between the determined instantaneous value of the model restriction object amount and the restricted restriction object amount.

35. (Original) The control device of a legged mobile robot according to Claim 31, further comprising second model input correcting means for determining a correction amount of the desired motion on the basis of at least the determined instantaneous value of the model restriction object amount and the permissible range, and then additionally inputting the determined correction amount to the second dynamic model.

36. (Original) The control device of a legged mobile robot according to Claim 35, further comprising:

a perturbation model that represents a relationship between a perturbative motion of the robot and a perturbation portion of a restriction object amount;
means for determining a manipulated variable of a floor reaction force

moment on the basis of at least the determined instantaneous value of the model restriction object amount and the permissible range; and

distributing means for dividing the determined manipulated variable of the floor reaction force moment into a floor reaction force moment correction amount of the desired floor reaction force to be supplied to the first dynamic model and a perturbation model manipulated variable to be supplied to the perturbation model,

wherein the second model input correcting means determines a correction amount of the desired motion by supplying the perturbation model manipulated variable to the perturbation model.

37. (Original) The control device of a legged mobile robot according to Claim 36, further comprising:

means for determining a required value of a manipulated variable of the floor reaction force moment on the basis of at least a state amount of the perturbation model,

wherein the means for determining a manipulated variable of the floor reaction force moment determines a manipulated variable of the floor reaction force moment to be supplied to the distributing means on the basis of at least the determined instantaneous value of the model restriction object amount, the permissible range, and the required value.

38. (Original) The control device of a legged mobile robot according to Claim 37, wherein the means for determining a required value of a manipulated variable of the floor reaction force moment sequentially determines the required value

according to a feedback control law on the basis of a difference between a state amount of the perturbation model and a desired value relative to the state amount.

39. (Original) The control device of a legged mobile robot according to Claim 36, wherein the perturbation model is a model that represents a relationship between a perturbative motion perturbing a component of an angular momentum changing rate of a robot about a vertical axis or about a floor surface normal line axis and a perturbation portion of the restriction object amount.

40. (Original) The control device of a legged mobile robot according to Claim 39, wherein the perturbative motion is a perturbative motion that maintains the position of a center-of-gravity of the robot substantially constant.

41. (Currently Amended) The control device of a legged mobile robot according to Claim 39 ~~or 40~~, wherein the perturbative motion is a perturbative motion of a body of the robot and/or an arm extended from the body.

42. (Original) The control device of a legged mobile robot according to Claim 36, wherein the means for determining a manipulated variable of the floor reaction force moment comprises means for determining, on the basis of at least the determined instantaneous value of the model restriction object amount, an estimated value of the restriction object amount in a case where the perturbation model manipulated variable is assumed to be zero, and means for comparing the determined estimated value with the permissible range to determine, on the basis of

the comparison, a restricted restriction object amount limited to the permissible range, and determines the manipulated variable of the floor reaction force moment on the basis of at least a difference between the determined instantaneous value of the model restriction object amount and the restricted restriction object amount.

43. (Original) The control device of a legged mobile robot according to Claim 37, wherein the means for determining the manipulated variable of the floor reaction force moment comprises means for determining an estimated value of the restriction object amount in a case, where the perturbation model manipulated variable is assumed to agree with the required value, on the basis of at least the determined instantaneous value of the model restriction object amount and the required value, and means for comparing the determined estimated value with the permissible range to determine, on the basis of the comparison, a restricted restriction object amount limited to the permissible range, and determines the manipulated variable of the floor reaction force moment on the basis of at least a difference between the determined instantaneous value of the model restriction object amount and the restricted restriction object amount.

44. (Original) A control device for generating a desired gait of a legged mobile robot that travels by moving a plurality of legs extended from its body and for controlling an operation of the robot so as to make the robot follow the desired gait, comprising:

means for determining a compensating floor reaction force moment, which is an additional floor reaction force moment for bringing a difference between a desired

state amount related to a posture of the robot about a vertical axis or a floor surface normal line axis and an actual state amount of the robot close to zero on the basis of at least the difference;

permissible range setting means for setting a permissible range of a restriction object amount, the restriction object amount being a vertical component of a floor reaction force moment or a component in floor surface normal line direction of the floor reaction force moment to be applied to a robot in operation, following the desired gait;

desired floor reaction force provisional instantaneous value determining means for sequentially determining a provisional instantaneous value of at least a desired floor reaction force out of a desired motion and a desired floor reaction force constituting the desired gait;

first model calculating means for inputting at least the provisional instantaneous value of a desired floor reaction force to a first dynamic model representing a relationship between a motion of the robot and a floor reaction force so as to determine a first provisional instantaneous value of a desired motion as an output of the first dynamic model;

restricted second model calculating means, which is a means for determining a second provisional instantaneous value of a desired motion, and which determines the second provisional instantaneous value of the desired motion on the basis of at least a provisional instantaneous value of the desired floor reaction force such that an instantaneous value of a restriction object amount that is determined by predetermined calculation from a vertical component or a component in floor surface normal line direction of a floor reaction force moment, which balances with the

determined second provisional instantaneous value on a second dynamic model representing a relationship between a motion of a robot and a floor reaction force, and the compensating floor reaction force moment falls within the permissible range;

manipulated variable calculating means for determining a manipulated variable of a floor reaction force moment on the basis of at least a difference between a first provisional instantaneous value and a second provisional instantaneous value of the desired motion such that the difference approaches zero; and

model input correcting means for additionally inputting the manipulated variable of the floor reaction force moment to at least one of the first dynamic model and the second dynamic model,

wherein the second provisional instantaneous value of the desired motion is determined as a desired instantaneous value of the desired motion.

45. (Original) The control device of a legged mobile robot according to Claim 44, wherein the difference between the first provisional instantaneous value and the second provisional instantaneous value of the desired motion includes a difference in a state amount of a posture of a predetermined part of the robot about a vertical axis or a floor surface normal line axis.

46. (Original) The control device of a legged mobile robot according to Claim 44, further comprising means for determining a floor reaction force moment instantaneous value corresponding to an instantaneous value of a restriction object amount, which is determined from a vertical component or a component in floor

surface normal line direction of a floor reaction force moment substantially balancing with an instantaneous value of the desired motion on the second dynamic model and the compensating floor reaction force moment by the predetermined calculation, as an instantaneous value of a floor reaction force moment of a desired floor reaction force constituting the desired gait.

47. (Original) The control device of a legged mobile robot according to Claim 34, further comprising a third model calculating means for inputting at least a provisional instantaneous value of the desired floor reaction force to a third dynamic model representing a relationship between a motion of the robot and a floor reaction force so as to determine a third provisional instantaneous value of a desired motion as an output of the third dynamic model, wherein the means for determining a required value of a floor reaction force moment correction amount of the desired floor reaction force determines the required value on the basis of a difference between the determined desired instantaneous value of the desired motion and the third provisional instantaneous value of the desired motion such that the difference approximates to zero.

48. (Currently Amended) The control device of a legged mobile robot according to ~~any one of Claims 20, 31 and 44~~claim 20, further comprising slippage determining means for determining the occurrence of a slippage of the robot in operation, following the desired gait, wherein the permissible range setting means variably sets the permissible range according to a determination result of the slippage determining means.

49. (Original) The control device of a legged mobile robot according to Claim 48, wherein the slippage determining means determines the occurrence of a slippage on the basis of at least the ground speed of a distal portion of a leg in contact with the ground.

50. (Original) The control device of a legged mobile robot according to Claim 48, wherein the slippage determining means comprises means for determining, on the basis of at least a temporal changing rate of an actual floor reaction force acting on the leg in contact with the ground and the ground speed of a distal portion of the leg, an apparent spring constant of the leg, and determines the occurrence of a slippage on the basis of at least the apparent spring constant.

51. (Original) The control device of a legged mobile robot according to Claim 48, wherein the slippage determining means determines the occurrence of a slippage on the basis of at least a result obtained by passing an actual floor reaction force acting on the leg in contact with the ground through a band-pass filter having a frequency passing characteristic in a range near a predetermined frequency.

52. (New) The control device of a legged mobile robot according to Claim 3, wherein the correction amount of the predetermined provisional instantaneous value is a correction amount of a motion that changes a vertical component or a component in floor surface normal line direction of an angular momentum changing rate of the robot.

53. (New) The control device of a legged mobile robot according to Claim 52, wherein the motion that changes the vertical component or the component in floor surface normal line direction of the angular momentum changing rate of the robot is a motion of a body of the robot and/or an arm extended from the body of the robot.

54. (New) The control device of a legged mobile robot according to Claim 7, wherein the desired instantaneous value determining means determines an instantaneous value of the desired motion by adjusting a motion that changes a vertical component or a component in floor surface normal line direction of an angular momentum changing rate of the robot among motions of the robot in order to hold the restriction object amount, which depends on a floor reaction force moment balancing with the desired motion on the dynamic model and the compensating floor reaction force moment, within the permissible range.

55. (New) The control device of a legged mobile robot according to Claim 54, wherein the motion that changes a vertical component or a component in floor surface normal line direction of an angular momentum changing rate of the robot is a motion of a body of the robot and/or an arm extended from the body.

56. (New) The control device of a legged mobile robot according to claim 11, wherein the desired instantaneous value determining means determines an instantaneous value of the desired motion by correcting a motion for changing a

vertical component or a component in floor surface normal line direction of an angular momentum changing rate of the robot on the basis of a provisional instantaneous value of the desired motion.

57. (New) The control device of a legged mobile robot according to Claim 56, wherein the motion for changing a vertical component or a component in floor surface normal line direction of an angular momentum changing rate of the robot is a motion of a body of the robot and/or an arm extended from the body.

58. (New) The control device of a legged mobile robot according to claim 12, wherein the desired instantaneous value determining means determines an instantaneous value of the desired motion by correcting a motion for changing a vertical component or a component in floor surface normal line direction of an angular momentum changing rate of the robot on the basis of a provisional instantaneous value of the desired motion.

59. (New) The control device of a legged mobile robot according to Claim 58, wherein the motion for changing a vertical component or a component in floor surface normal line direction of an angular momentum changing rate of the robot is a motion of a body of the robot and/or an arm extended from the body.

60. (New) The control device of a legged mobile robot according to claim 6, wherein the state amount related to a posture of the robot includes a yaw angle or a yaw angular velocity of the body of the robot.

61. (New) The control device of a legged mobile robot according to claim 10, wherein the state amount related to a posture of the robot includes a yaw angle or a yaw angular velocity of the body of the robot.

62. (New) The control device of a legged mobile robot according to claim 6, further comprising slippage determining means for determining occurrence of a slippage of the robot, wherein the permissible range setting means variably sets the permissible range according to a determination result of the slippage determining means.

63. (New) The control device of a legged mobile robot according to Claim 62, wherein the slippage determining means determines the occurrence of a slippage on the basis of at least the ground speed of a distal portion of a leg in contact with the ground.

64. (New) The control device of a legged mobile robot according to Claim 62, wherein the slippage determining means comprises means for determining, on the basis of at least a temporal changing rate of an actual floor reaction force acting on a leg in contact with the ground and the ground speed of a distal portion of the leg, an apparent spring constant of the leg, and determines the occurrence of a slippage on the basis of at least the apparent spring constant.

65. (New) The control device of a legged mobile robot according to Claim 62, wherein the slippage determining means determines the occurrence of a

slippage on the basis of at least a result obtained by passing an actual floor reaction force acting on a leg in contact with the ground through a band-pass filter having a frequency passing characteristic in a range near a predetermined frequency.

66. (New) The control device of a legged mobile robot according to claim 10, further comprising slippage determining means for determining occurrence of a slippage of the robot, wherein the permissible range setting means variably sets the permissible range according to a determination result of the slippage determining means.

67. (New) The control device of a legged mobile robot according to Claim 66, wherein the slippage determining means determines the occurrence of a slippage on the basis of at least the ground speed of a distal portion of a leg in contact with the ground.

68. (New) The control device of a legged mobile robot according to Claim 66, wherein the slippage determining means comprises means for determining, on the basis of at least a temporal changing rate of an actual floor reaction force acting on a leg in contact with the ground and the ground speed of a distal portion of the leg, an apparent spring constant of the leg, and determines the occurrence of a slippage on the basis of at least the apparent spring constant.

69. (New) The control device of a legged mobile robot according to Claim 66, wherein the slippage determining means determines the occurrence of a

slippage on the basis of at least a result obtained by passing an actual floor reaction force acting on a leg in contact with the ground through a band-pass filter having a frequency passing characteristic in a range near a predetermined frequency.

70. (New) The control device of a legged mobile robot according to Claim 29, wherein the perturbative motion is a perturbative motion of a body of the robot and/or an arm extended from the body.

71. (New) The control device of a legged mobile robot according to Claim 40, wherein the perturbative motion is a perturbative motion of a body of the robot and/or an arm extended from the body.

72. (New) The control device of a legged mobile robot according to claim 31, further comprising slippage determining means for determining the occurrence of a slippage of the robot in operation, following the desired gait, wherein the permissible range setting means variably sets the permissible range according to a determination result of the slippage determining means.

73. (New) The control device of a legged mobile robot according to Claim 72, wherein the slippage determining means determines the occurrence of a slippage on the basis of at least the ground speed of a distal portion of a leg in contact with the ground.

74. (New) The control device of a legged mobile robot according to Claim

72, wherein the slippage determining means comprises means for determining, on the basis of at least a temporal changing rate of an actual floor reaction force acting on the leg in contact with the ground and the ground speed of a distal portion of the leg, an apparent spring constant of the leg, and determines the occurrence of a slippage on the basis of at least the apparent spring constant.

75. (New) The control device of a legged mobile robot according to Claim 72, wherein the slippage determining means determines the occurrence of a slippage on the basis of at least a result obtained by passing an actual floor reaction force acting on the leg in contact with the ground through a band-pass filter having a frequency passing characteristic in a range near a predetermined frequency.

76. (New) The control device of a legged mobile robot according to claim 44, further comprising slippage determining means for determining the occurrence of a slippage of the robot in operation, following the desired gait, wherein the permissible range setting means variably sets the permissible range according to a determination result of the slippage determining means.

77. (New) The control device of a legged mobile robot according to Claim 76, wherein the slippage determining means determines the occurrence of a slippage on the basis of at least the ground speed of a distal portion of a leg in contact with the ground.

78. (New) The control device of a legged mobile robot according to Claim

76, wherein the slippage determining means comprises means for determining, on the basis of at least a temporal changing rate of an actual floor reaction force acting on the leg in contact with the ground and the ground speed of a distal portion of the leg, an apparent spring constant of the leg, and determines the occurrence of a slippage on the basis of at least the apparent spring constant.

79. (New) The control device of a legged mobile robot according to Claim 76, wherein the slippage determining means determines the occurrence of a slippage on the basis of at least a result obtained by passing an actual floor reaction force acting on the leg in contact with the ground through a band-pass filter having a frequency passing characteristic in a range near a predetermined frequency.